

FIG. 1

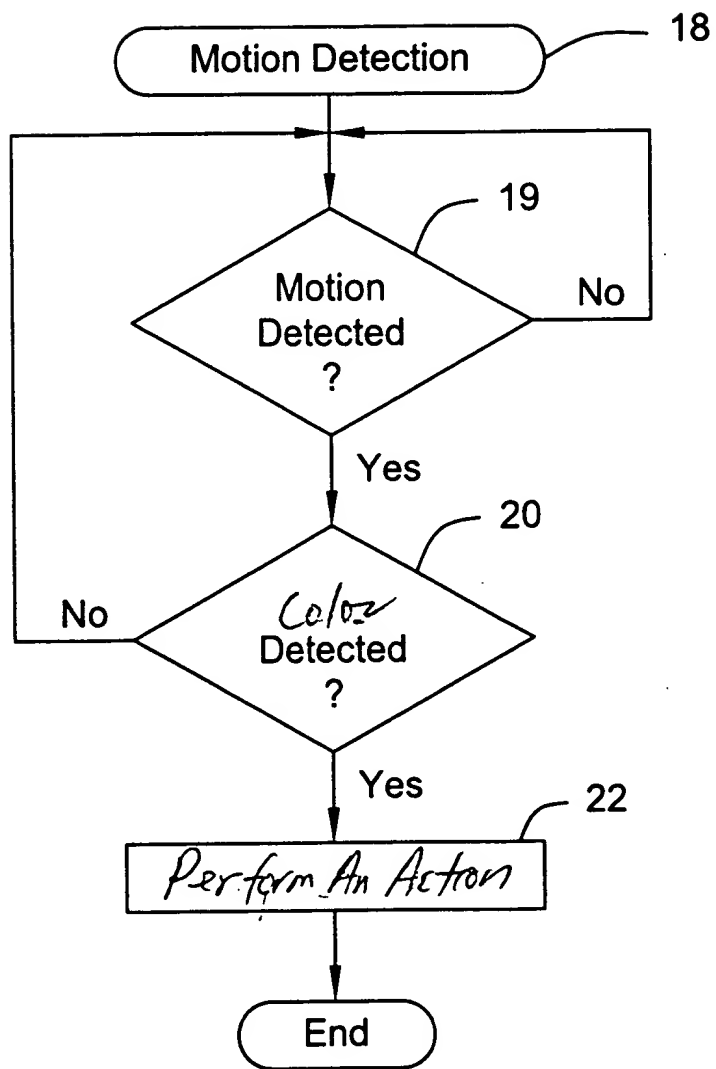


FIG. 2

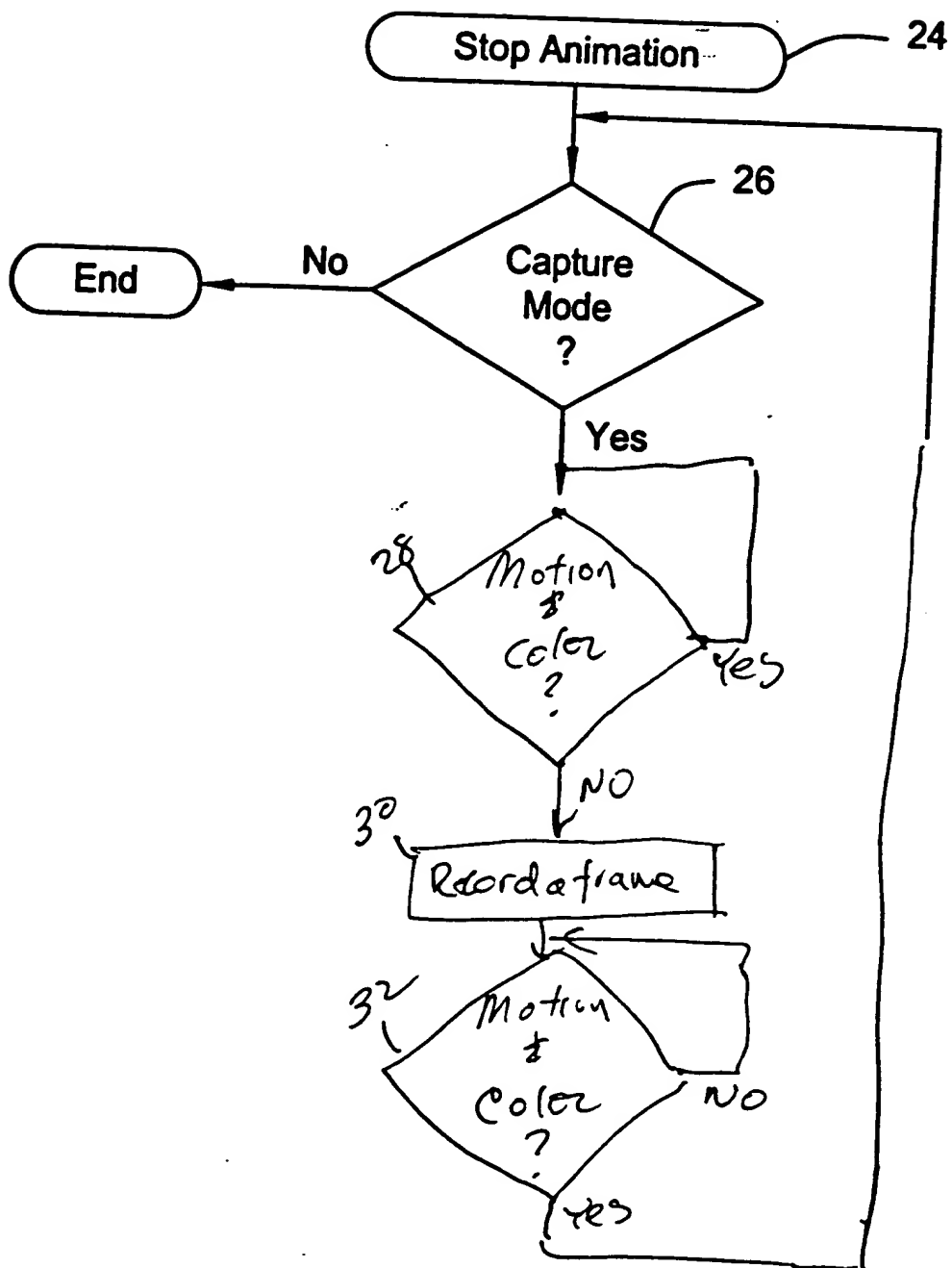


FIG. 3

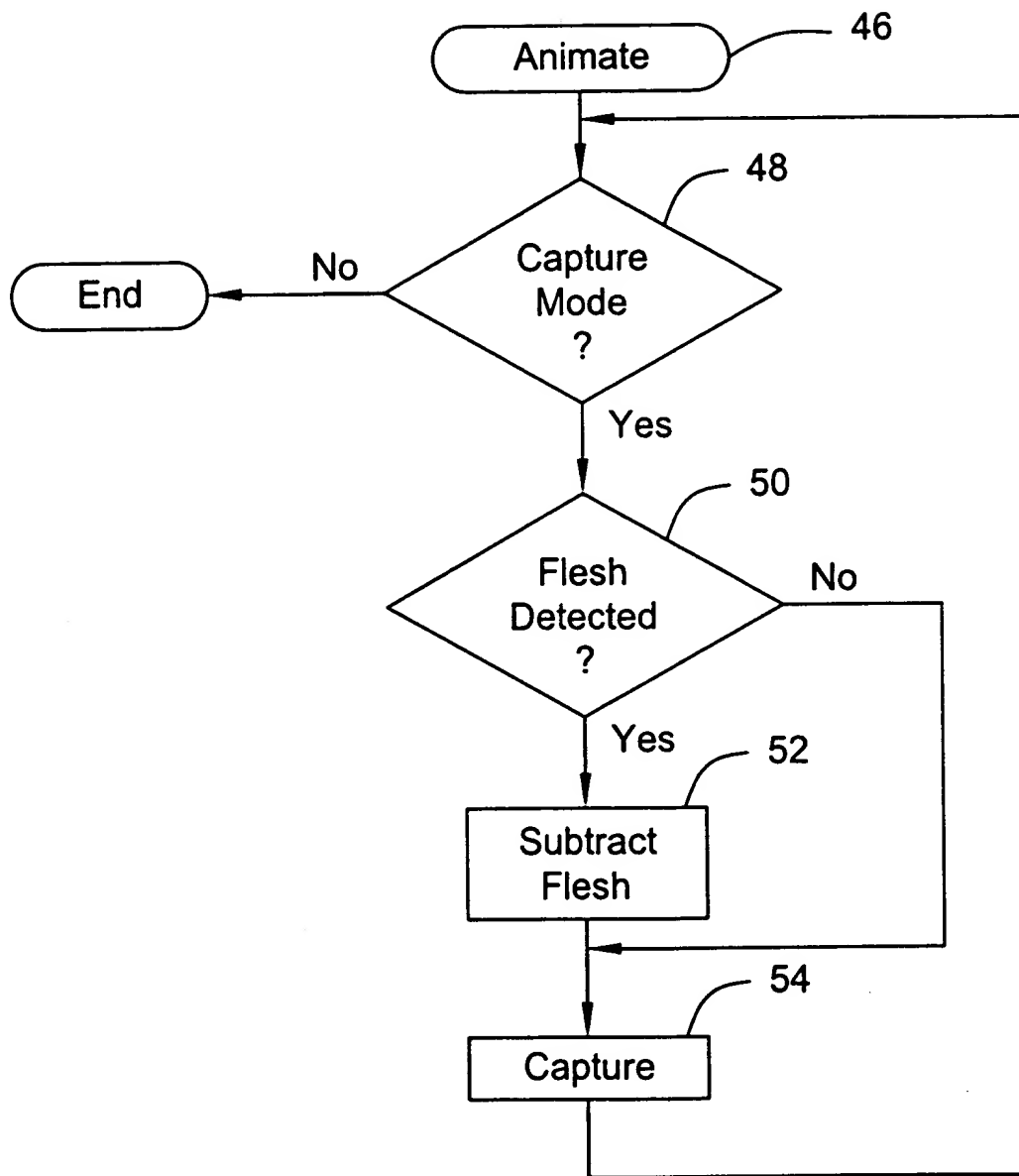


FIG. 4

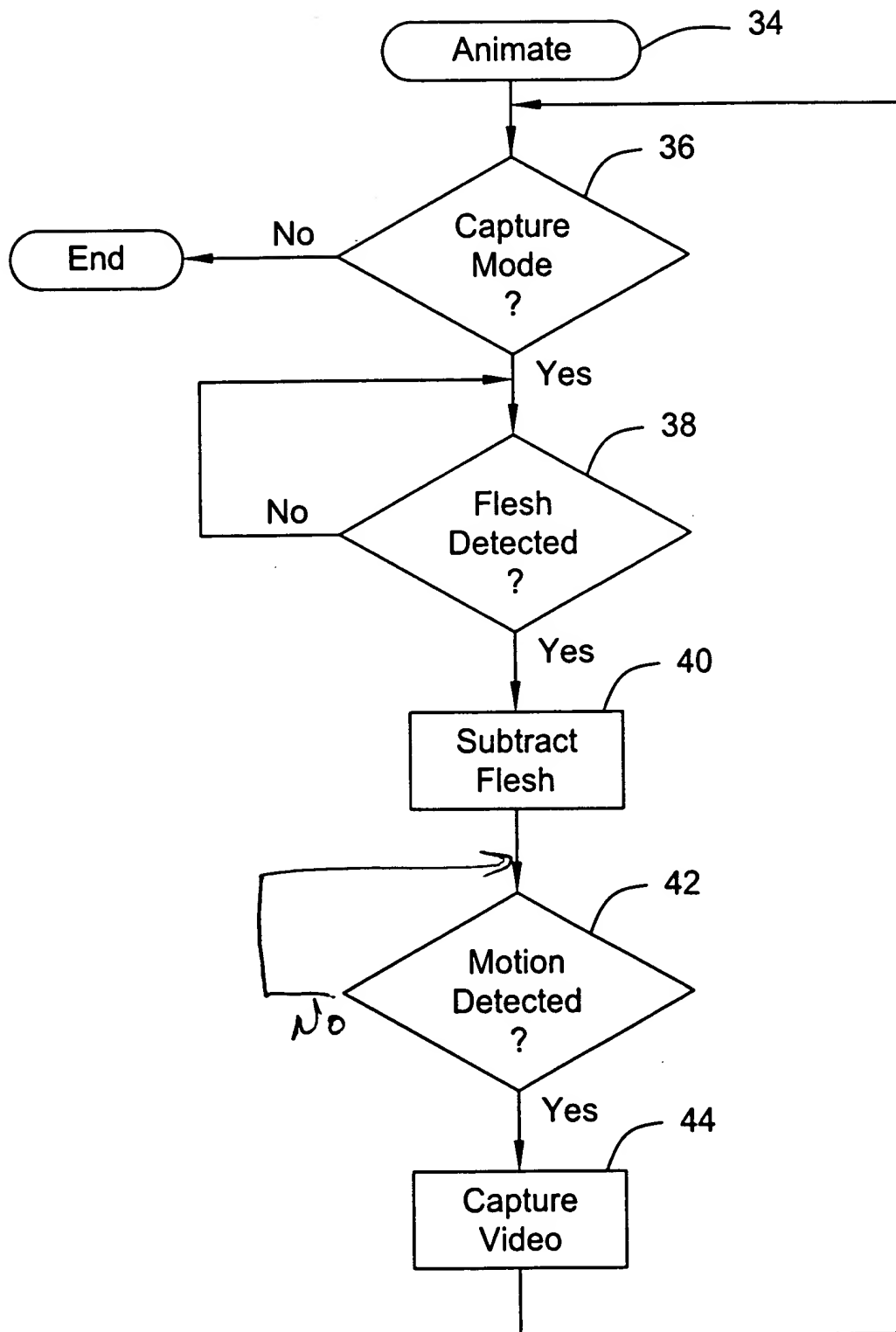


FIG. 5

FIG. 6A is a schematic diagram of a prosthetic arm and hand assembly. The assembly includes a torso section (10) with a central body (12) and two arms (14, 16). The right arm (14) is extended forward and slightly downward, ending in a hand (18). The left arm (16) is extended forward and slightly upward, ending in a hand (20). The hands (18, 20) are shown in a relaxed, slightly curled position. The torso section (10) is connected to a base (22) which is mounted on a support structure (24). The support structure (24) includes a central vertical post (26) and two side posts (28, 30). The side posts (28, 30) are connected to the base (22) and extend upwards. The central post (26) is connected to the base (22) and extends upwards. The support structure (24) is designed to provide a stable base for the prosthetic arm and hand assembly.

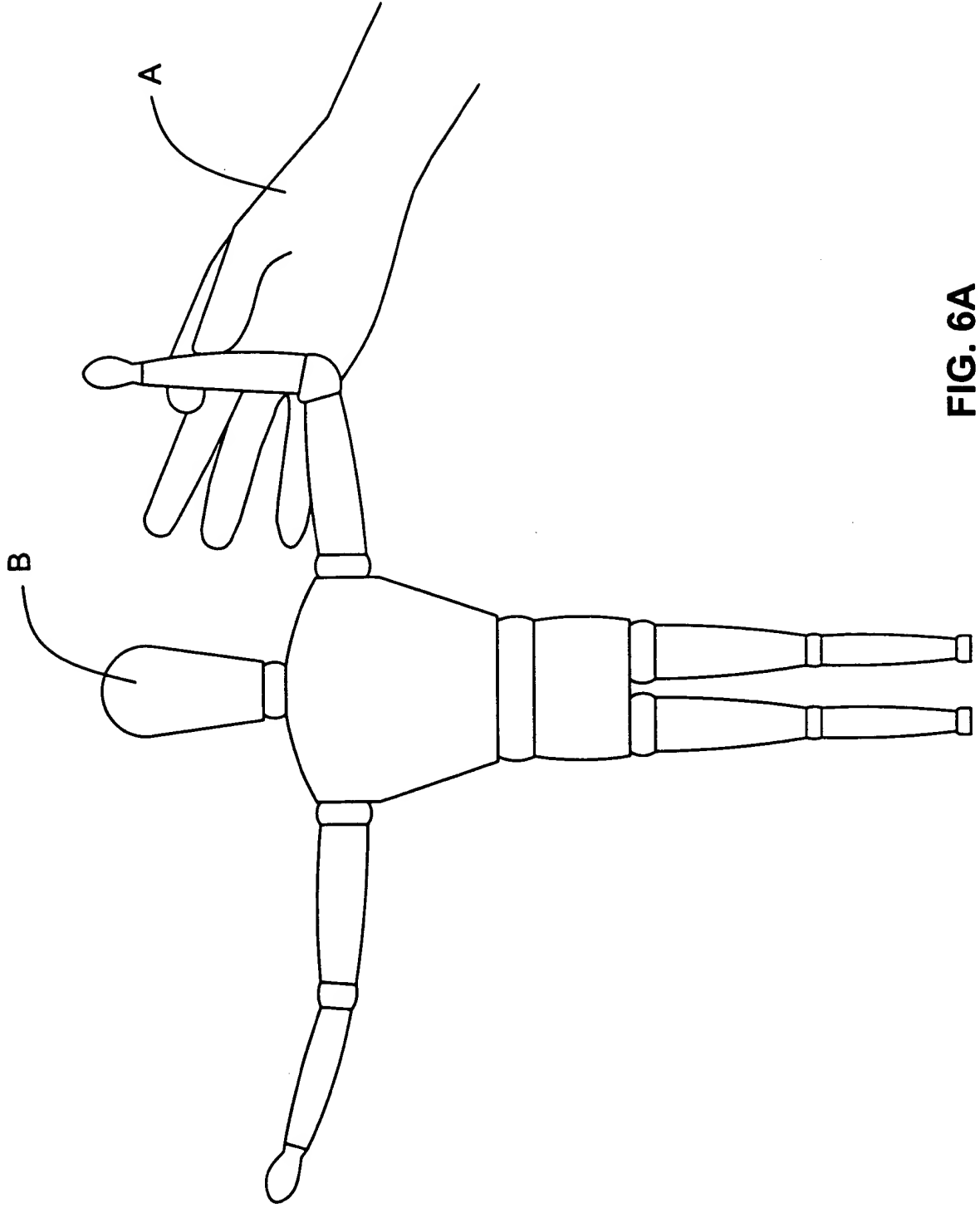


FIG. 6A

FIG. 6B is a perspective view of the robot 100 in a standing posture. The robot 100 includes a head 110, a torso 120, two arms 130, and two legs 140. The head 110 is connected to the torso 120. The torso 120 is connected to the arms 130 and the legs 140. The arms 130 are connected to the hands 150. The legs 140 are connected to the feet 160. The robot 100 is shown in a standing posture with its arms 130 extended outwards and its legs 140 straight.

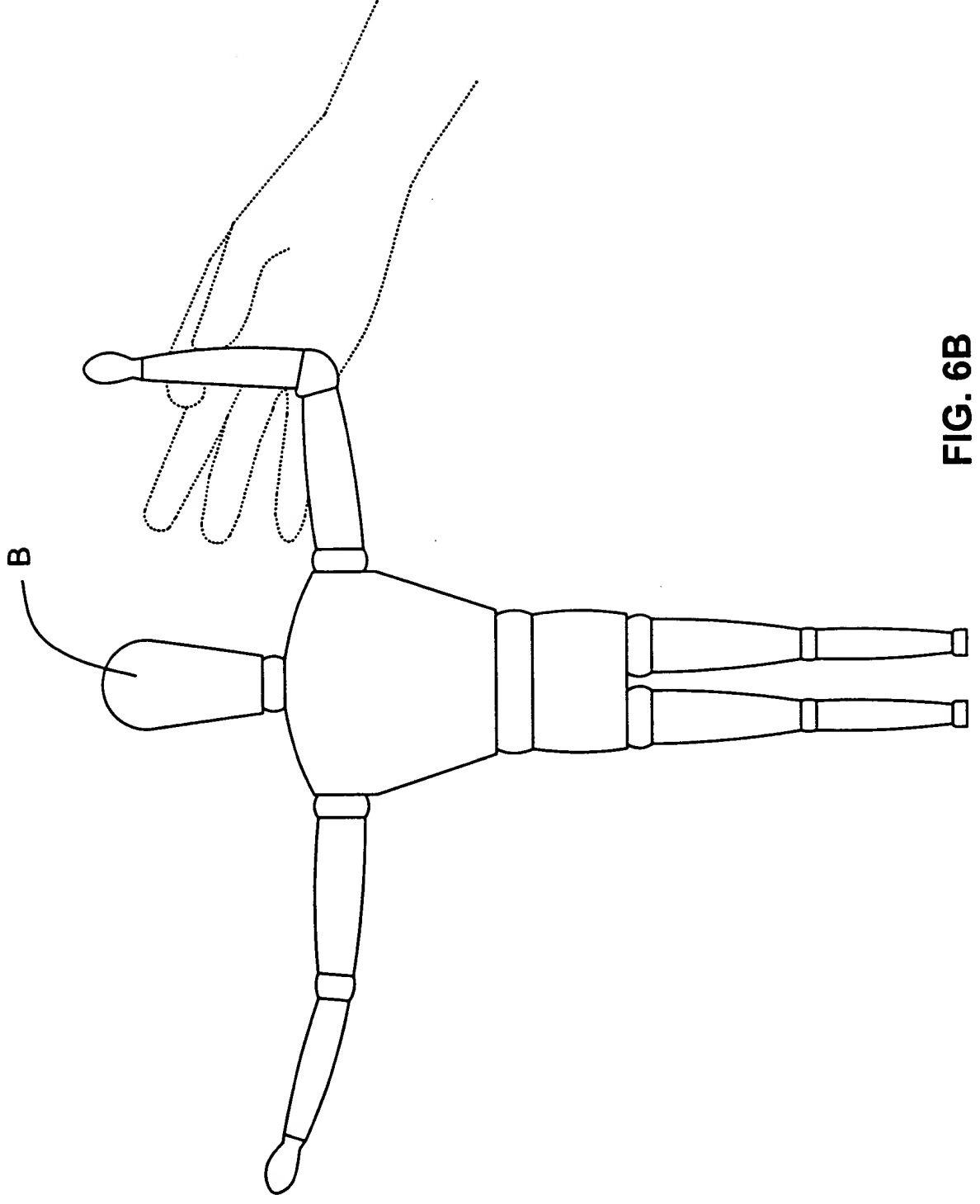


FIG. 6B

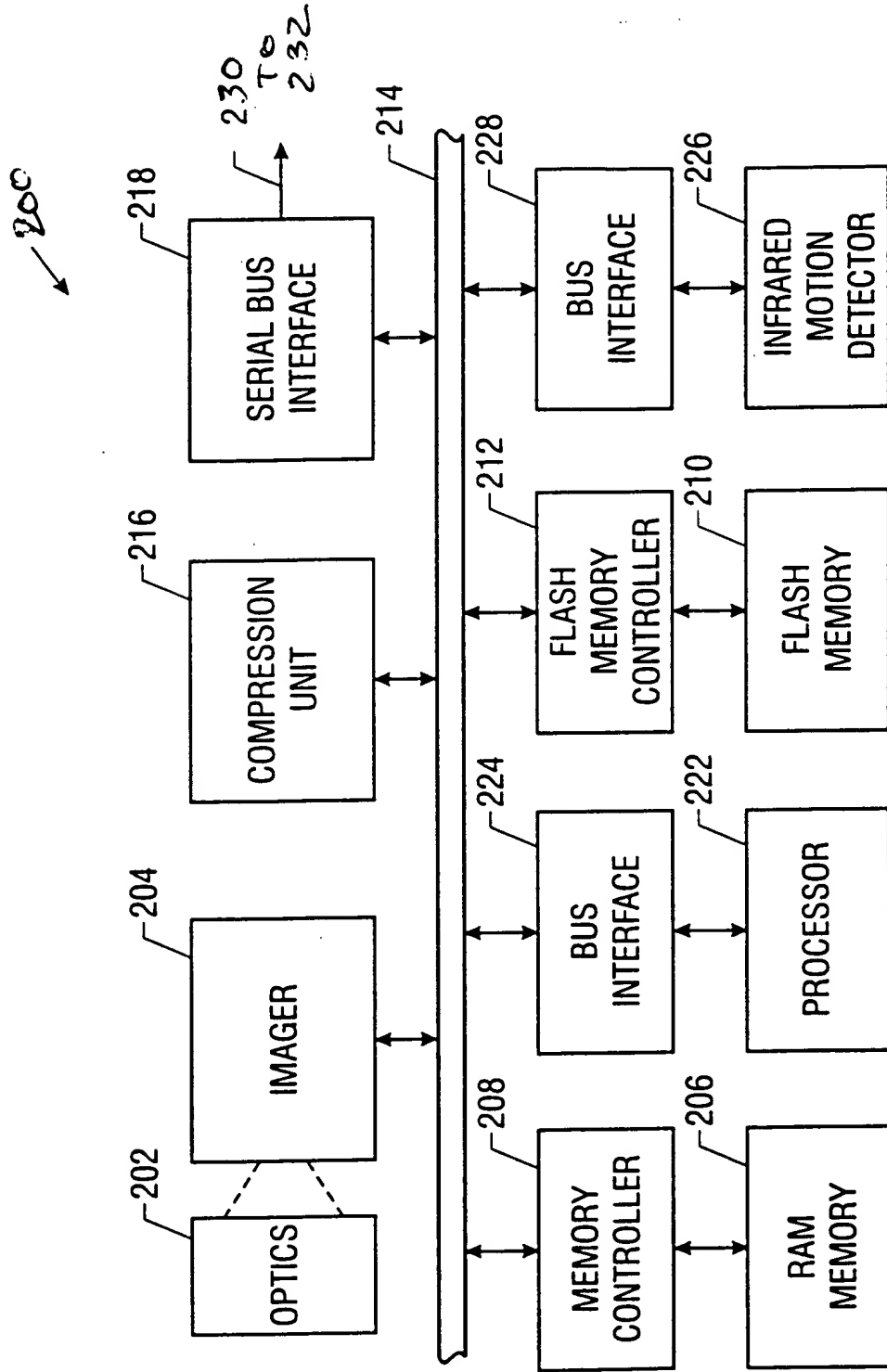


FIG. 7

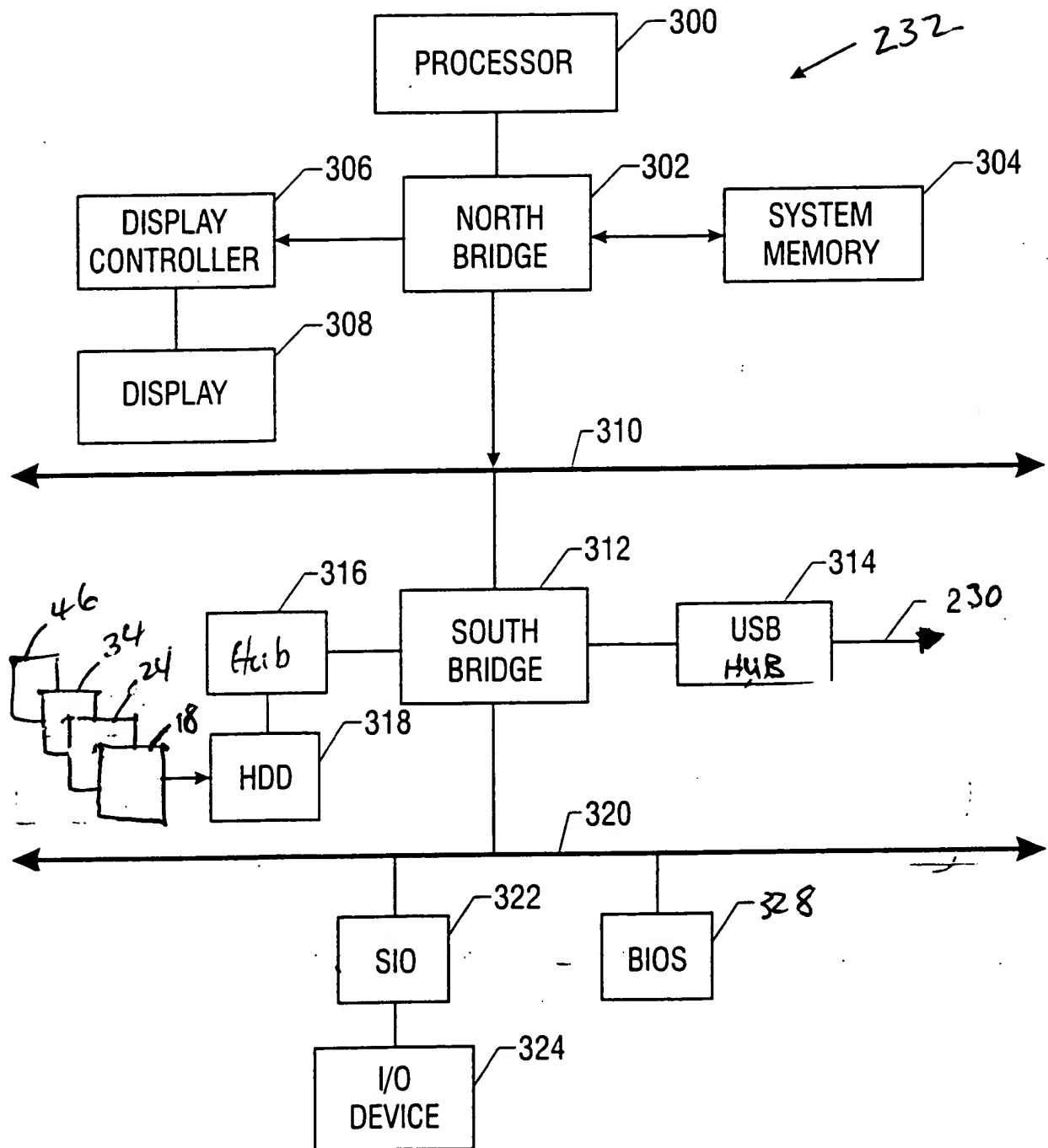


FIG. 8

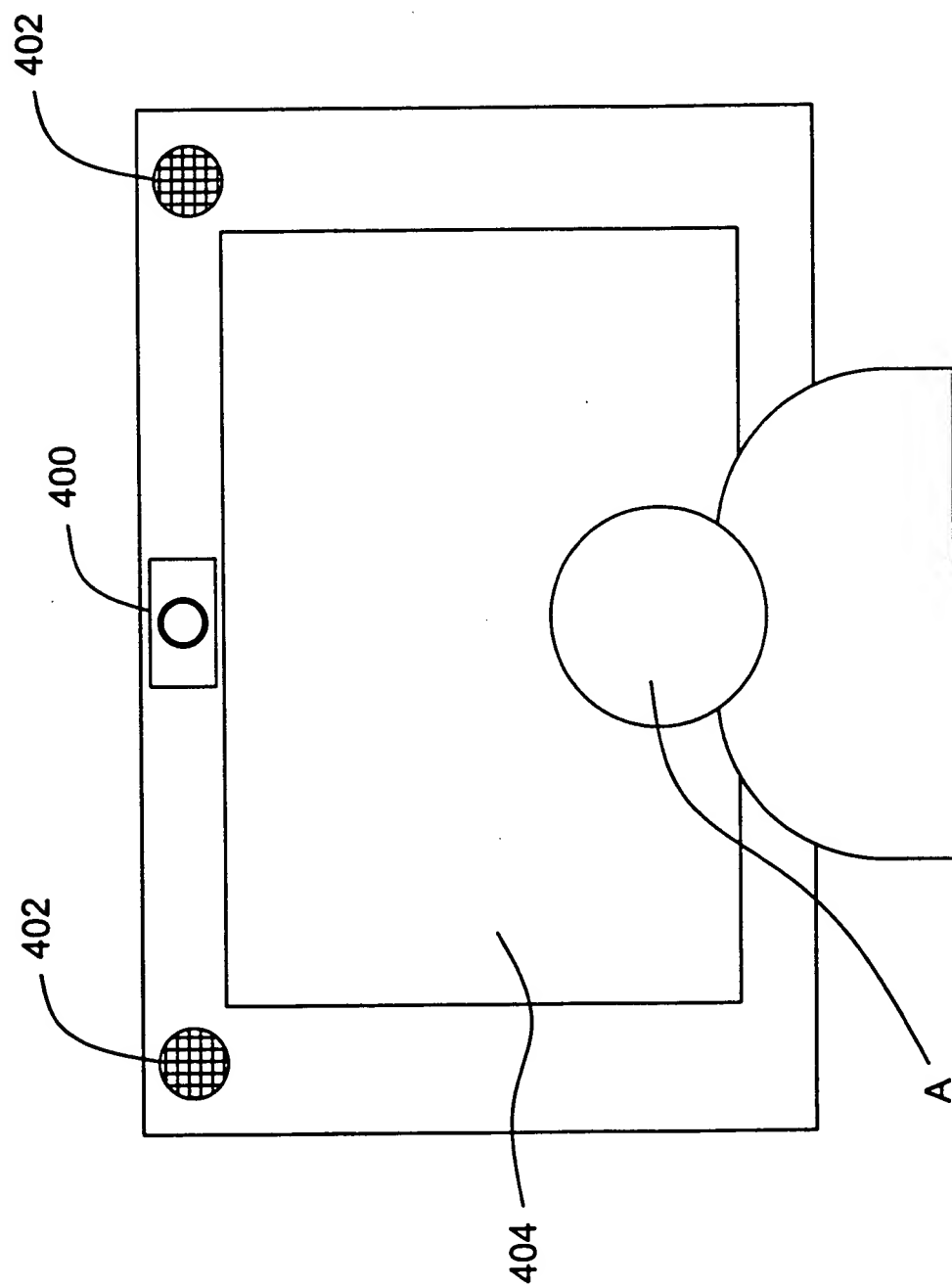


FIG. 9

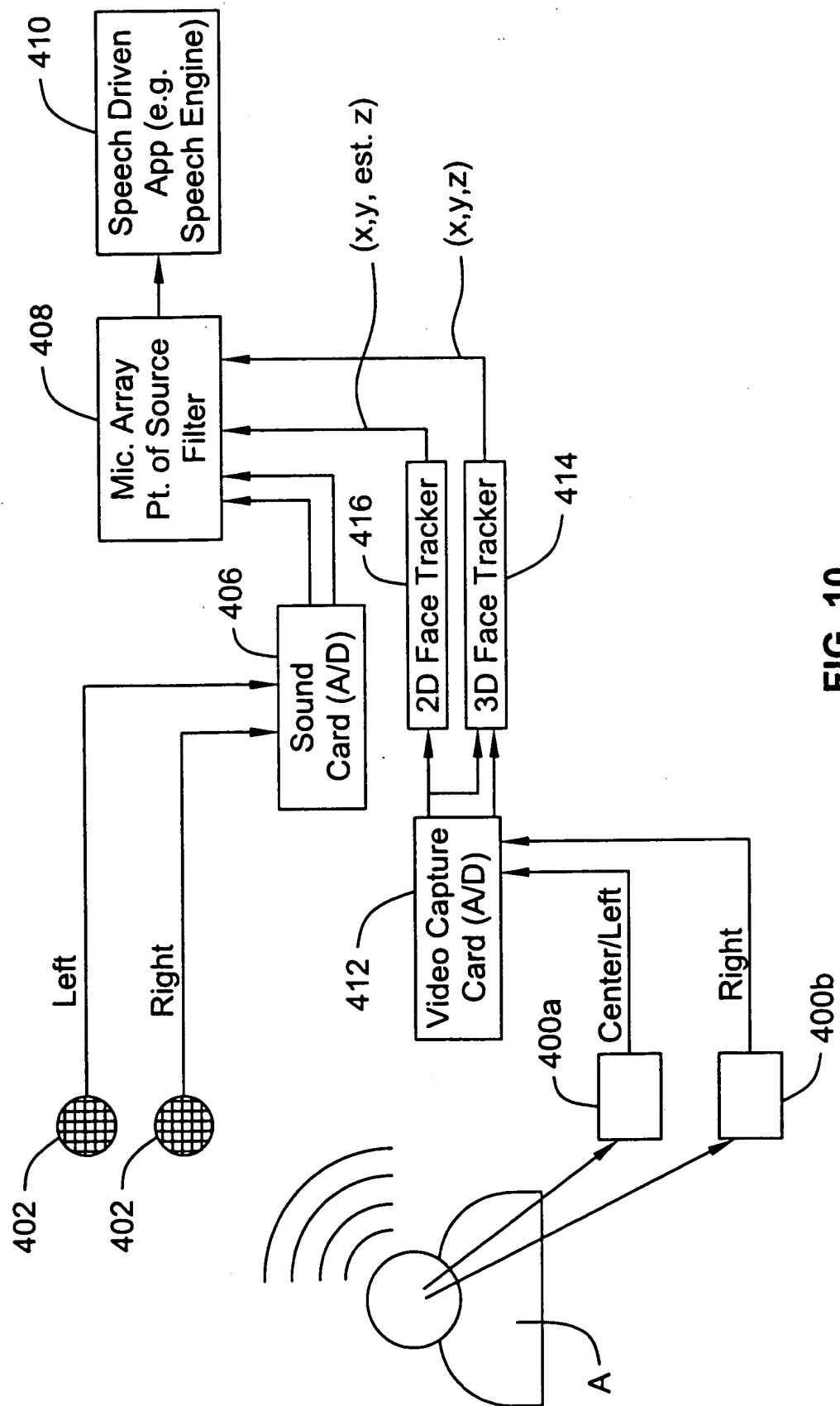


FIG. 10

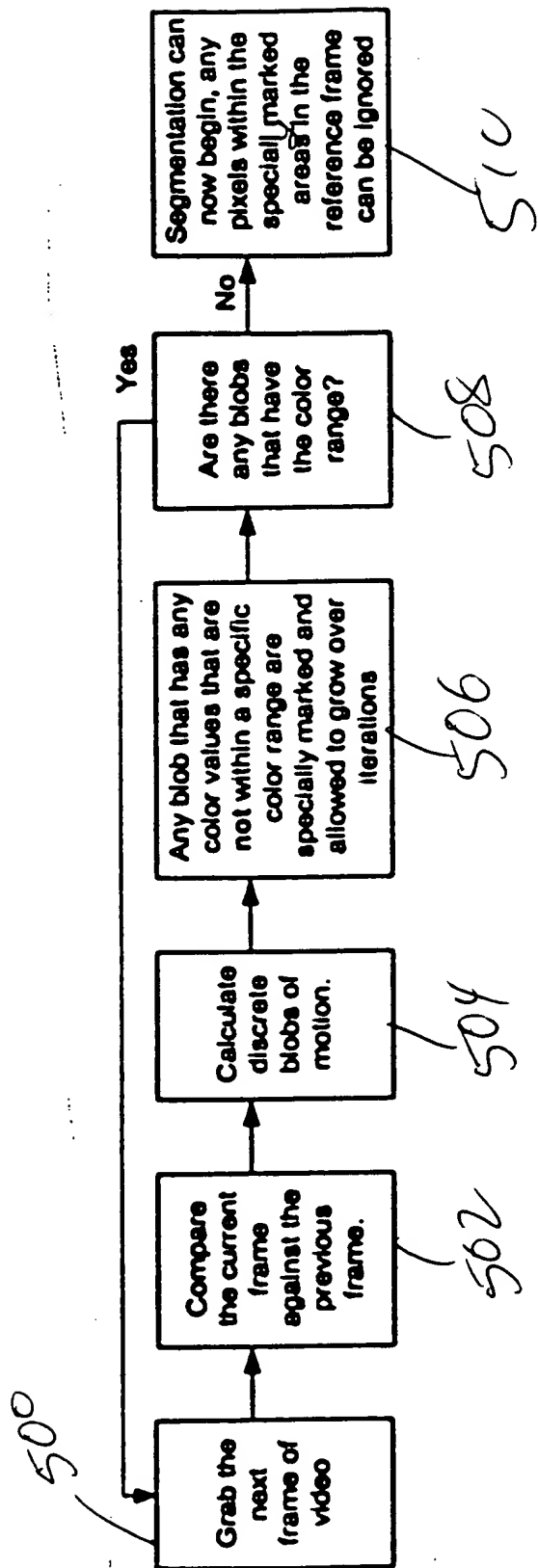


Figure 11